

100

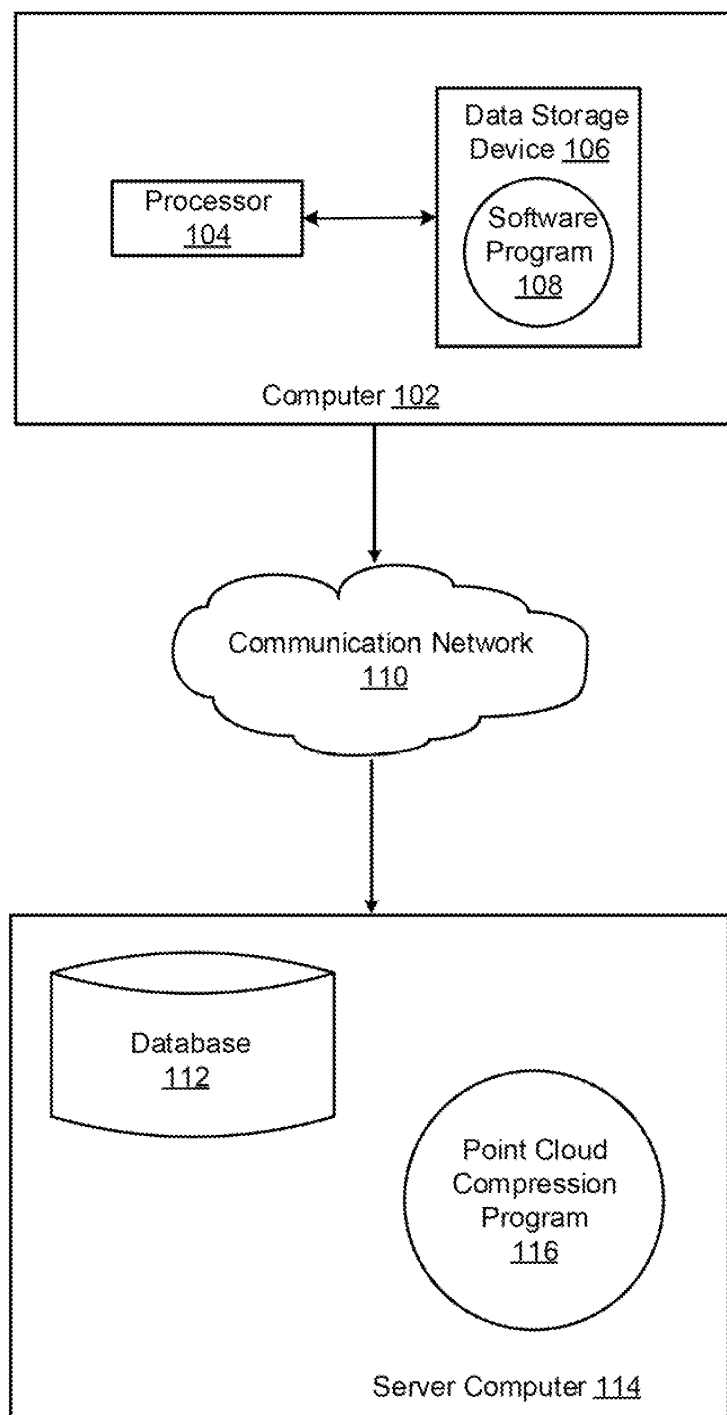


FIG. 1

200A →

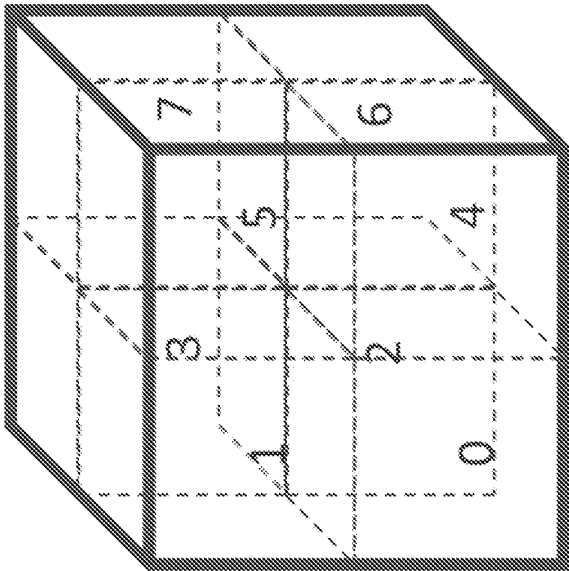


FIG. 2A

200B

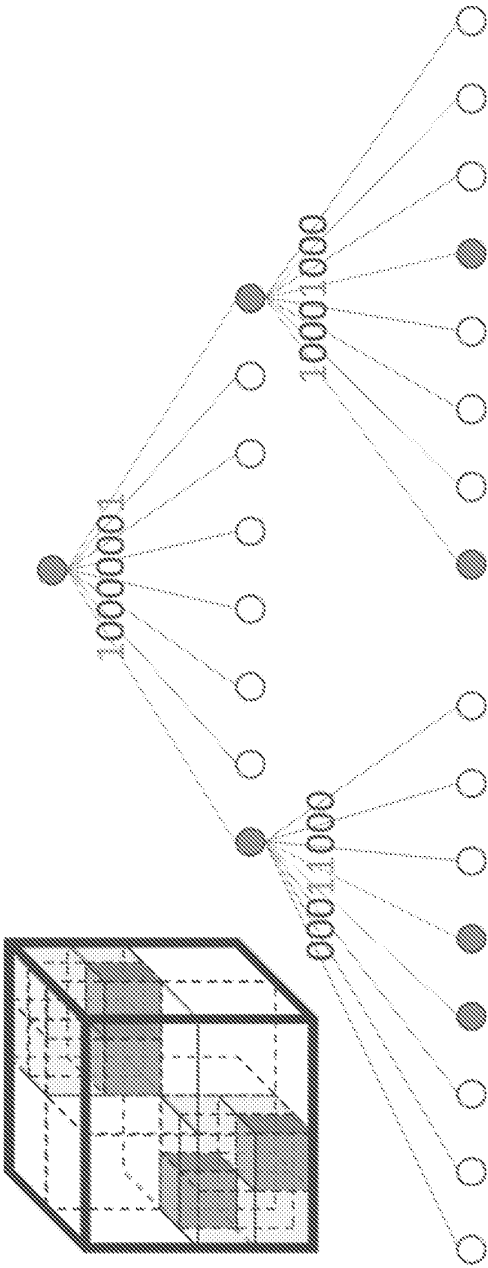


FIG. 2B

200C

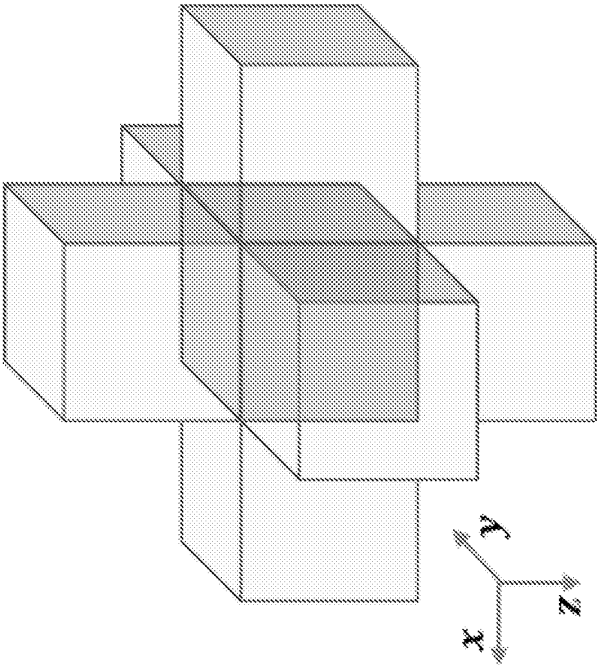


FIG. 2C

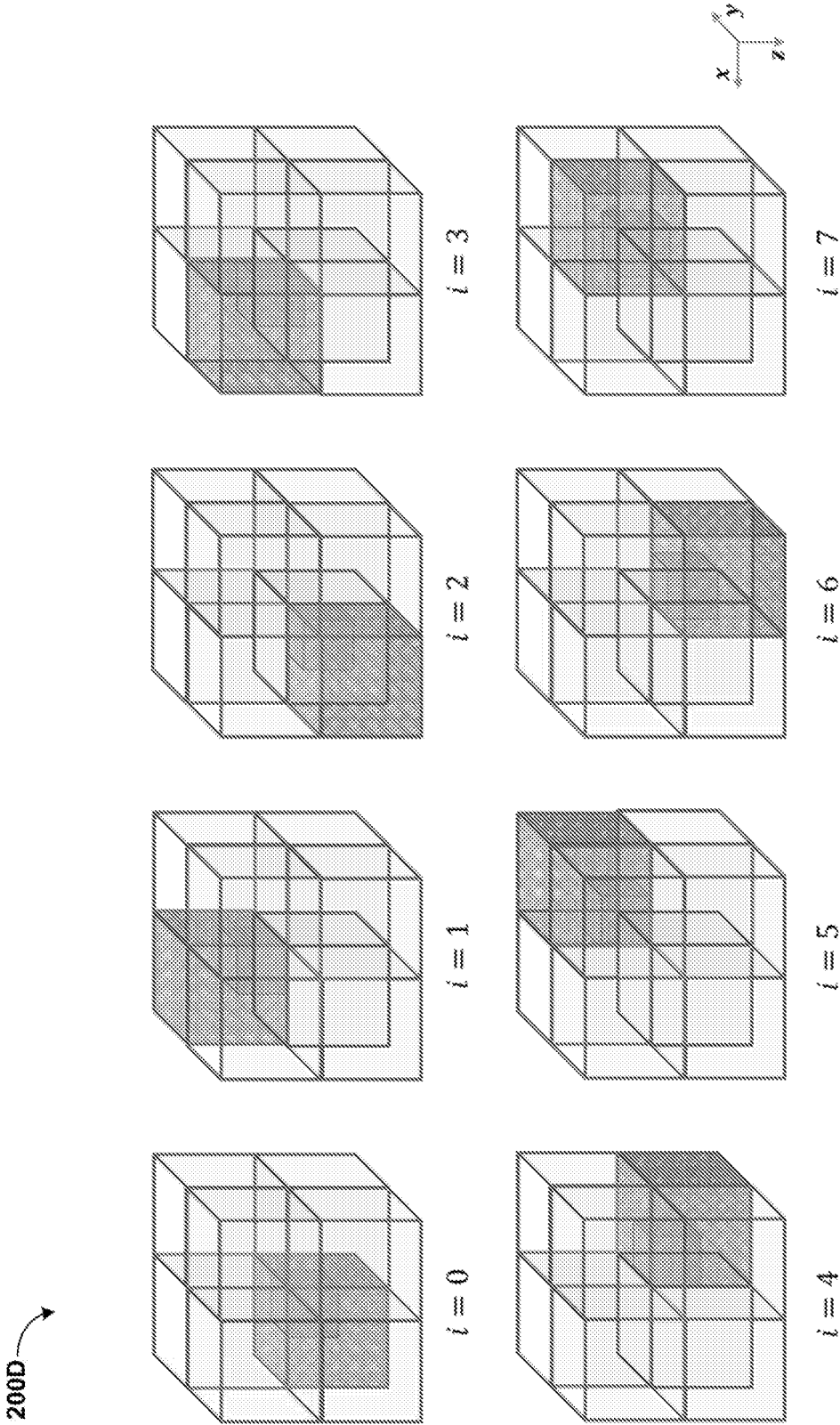


FIG. 2D

200E

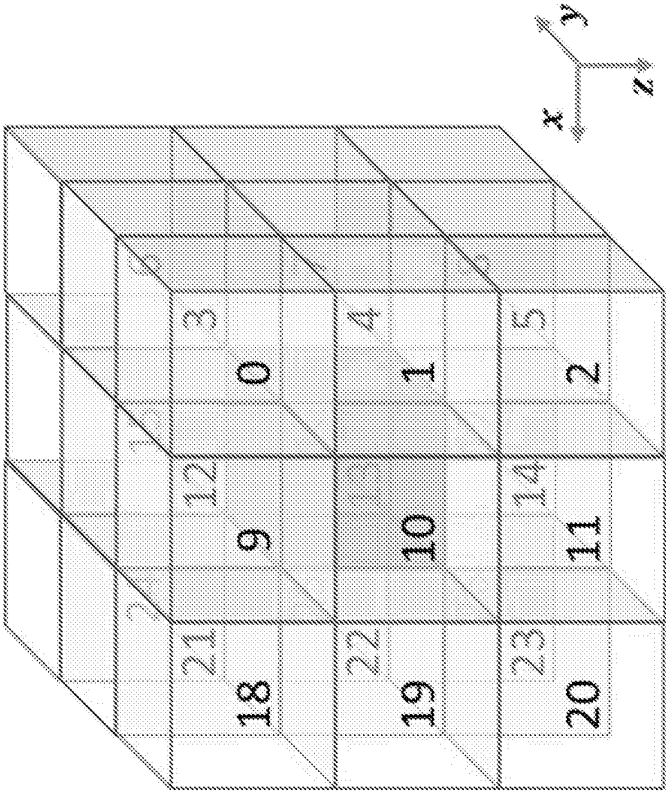


FIG. 2E

200F

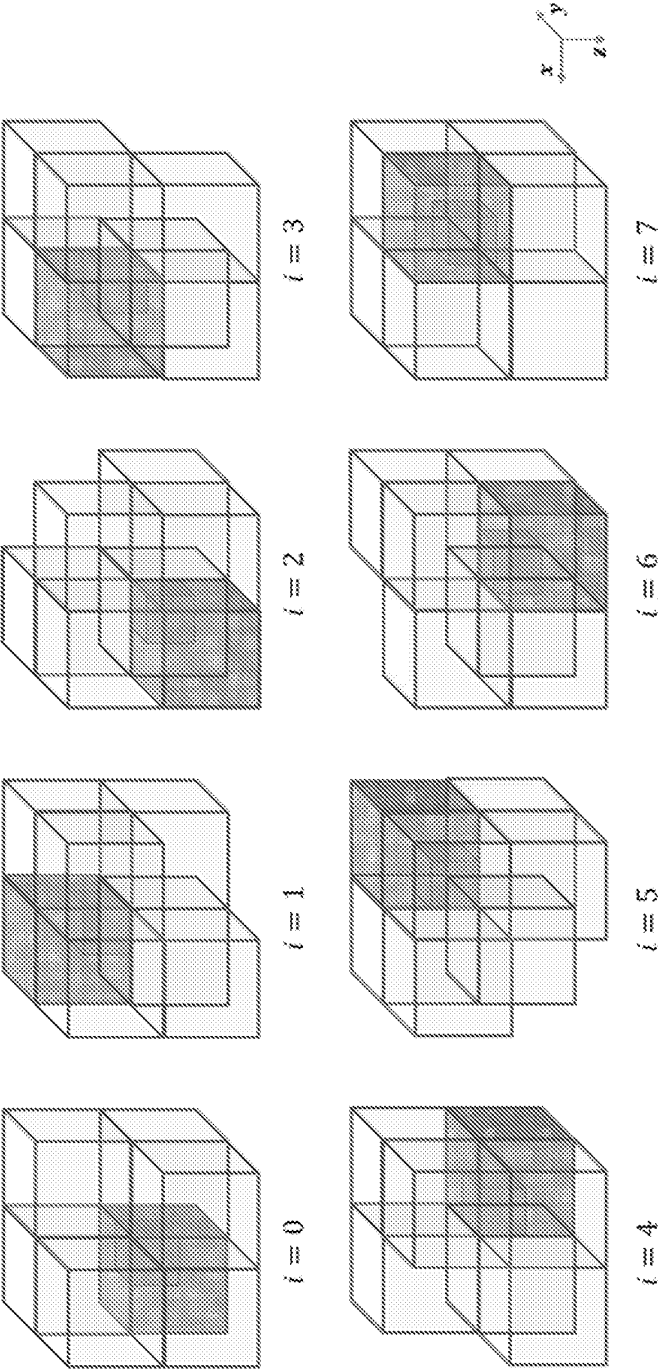


FIG. 2F

200G

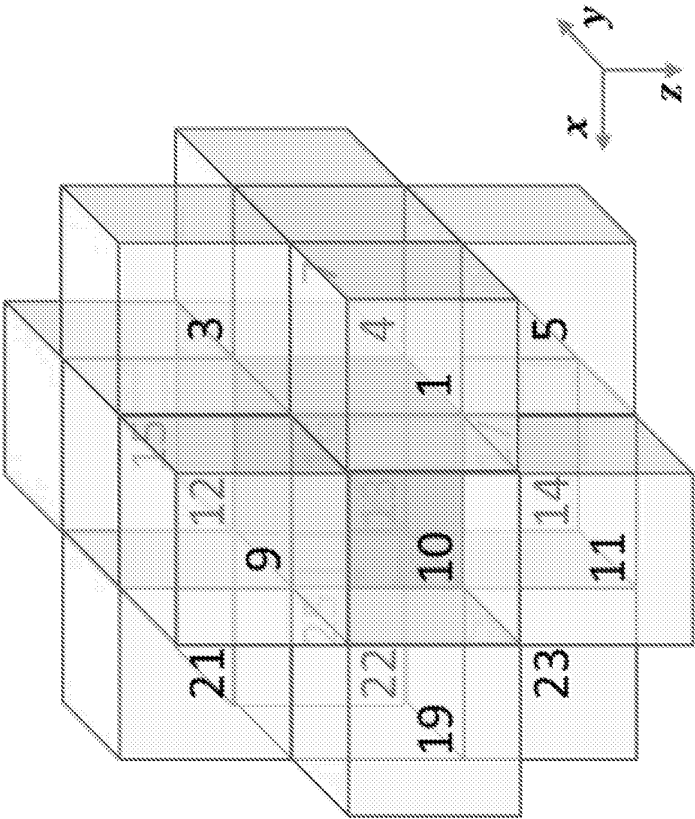


FIG. 2G

200H

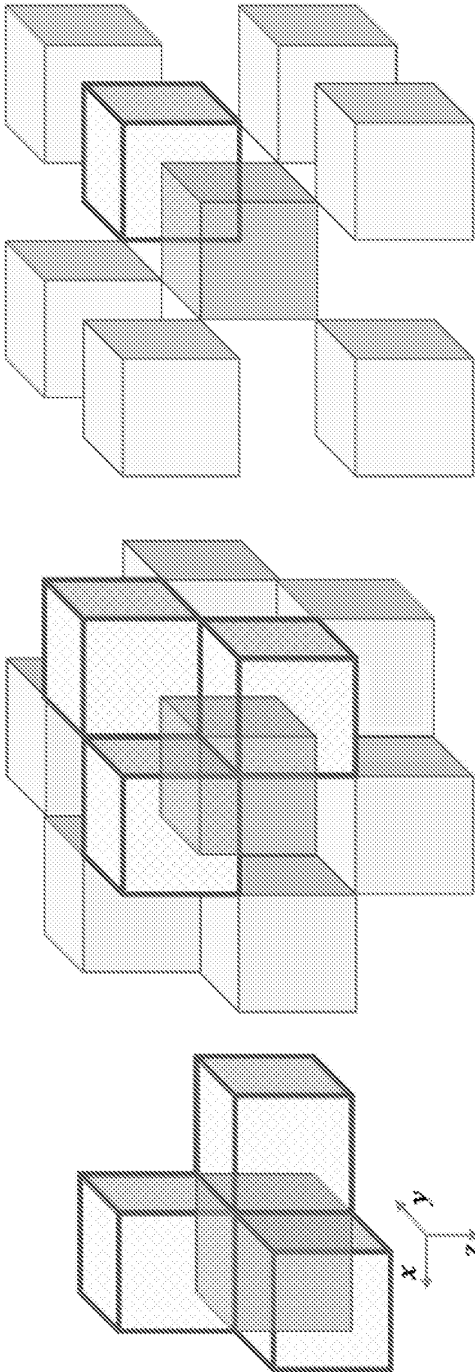


FIG. 2H

300A →

P_{ij}	$j = 0$	$j = 1$	$j = 2$	$j = 3$	$j = 4$	$j = 5$
$i = 0$	4	10	12	1	3	9
$i = 1$	4	10	14	1	5	11
$i = 2$	4	16	12	7	3	15
$i = 3$	4	16	14	7	5	17
$i = 4$	22	10	12	19	21	9
$i = 5$	22	10	14	19	23	11
$i = 6$	22	16	12	25	21	15
$i = 7$	22	16	14	25	23	17

FIG. 3A

300B

geometry_parameter_set() {	Descriptor
gps_geom_parameter_set_id	ue(v)
gps_seq_parameter_set_id	ue(v)
gps_box_present_flag	u(1)
if(gps_box_present_flag){	
gps_gsh_box_log2_scale_present_flag	u(1)
if(gps_gsh_box_log2_scale_present_flag == 0)	
gps_gsh_box_log2_scale	ue(v)
}	
unique_geometry_points_flag	u(1)
neighbour_context_restriction_flag	u(1)
inferred_direct_coding_mode_enabled_flag	u(1)
bitwise_occupancy_coding_flag	u(1)
adjacent_child_contextualization_enabled_flag	u(1)
log2_neighbour_avail_boundary	ue(v)
log2_intra_pred_max_node_size	ue(v)
log2_trisoup_node_size	ue(v)
gps_context_reduction_level	ue(v)
gps_extension_present_flag	u(1)
if(gps_extension_present_flag)	
while(more_data_in_byte_stream())	
gps_extension_data_flag	u(1)
byte_alignment()	
}	

FIG. 3B

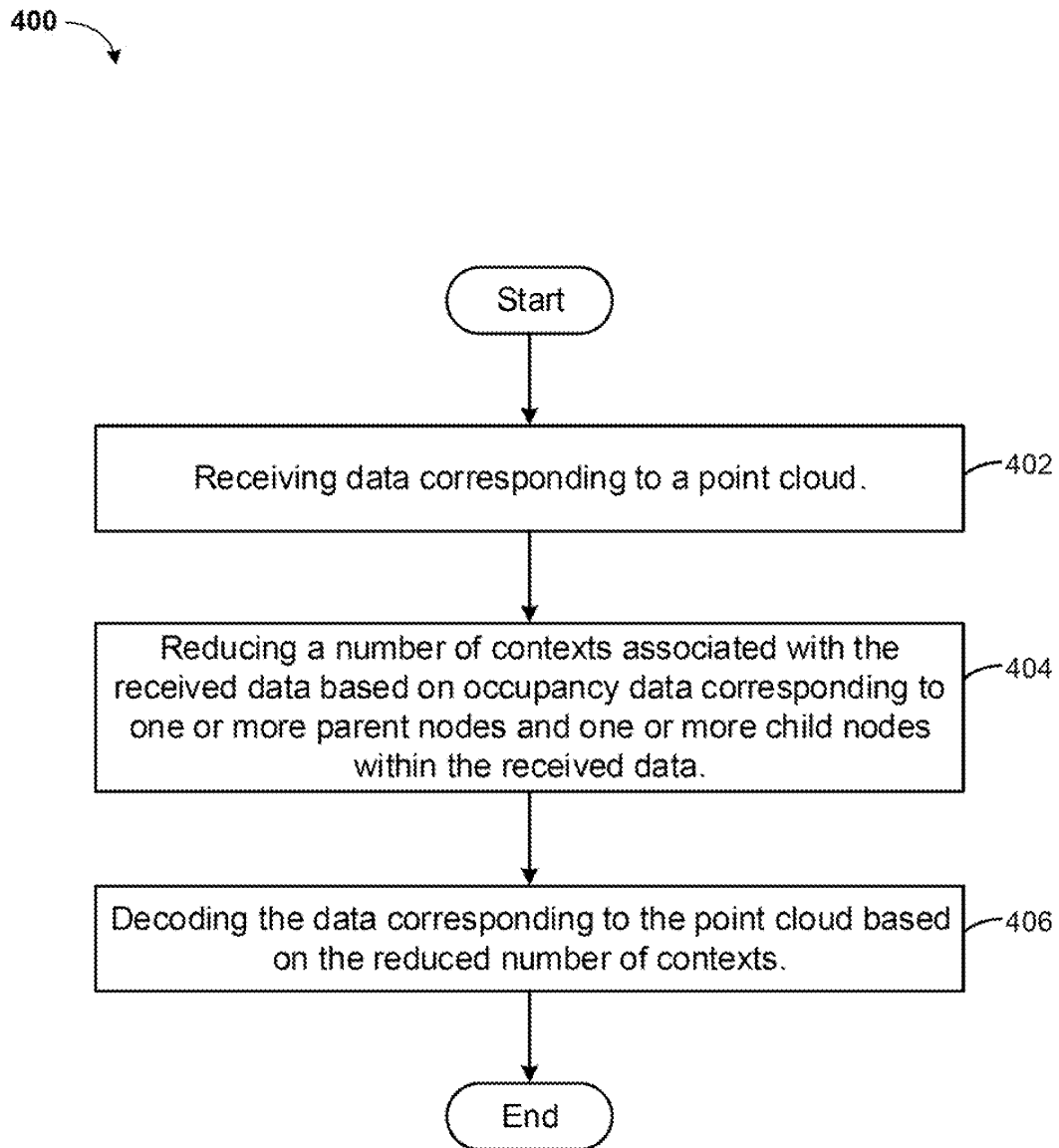


FIG. 4

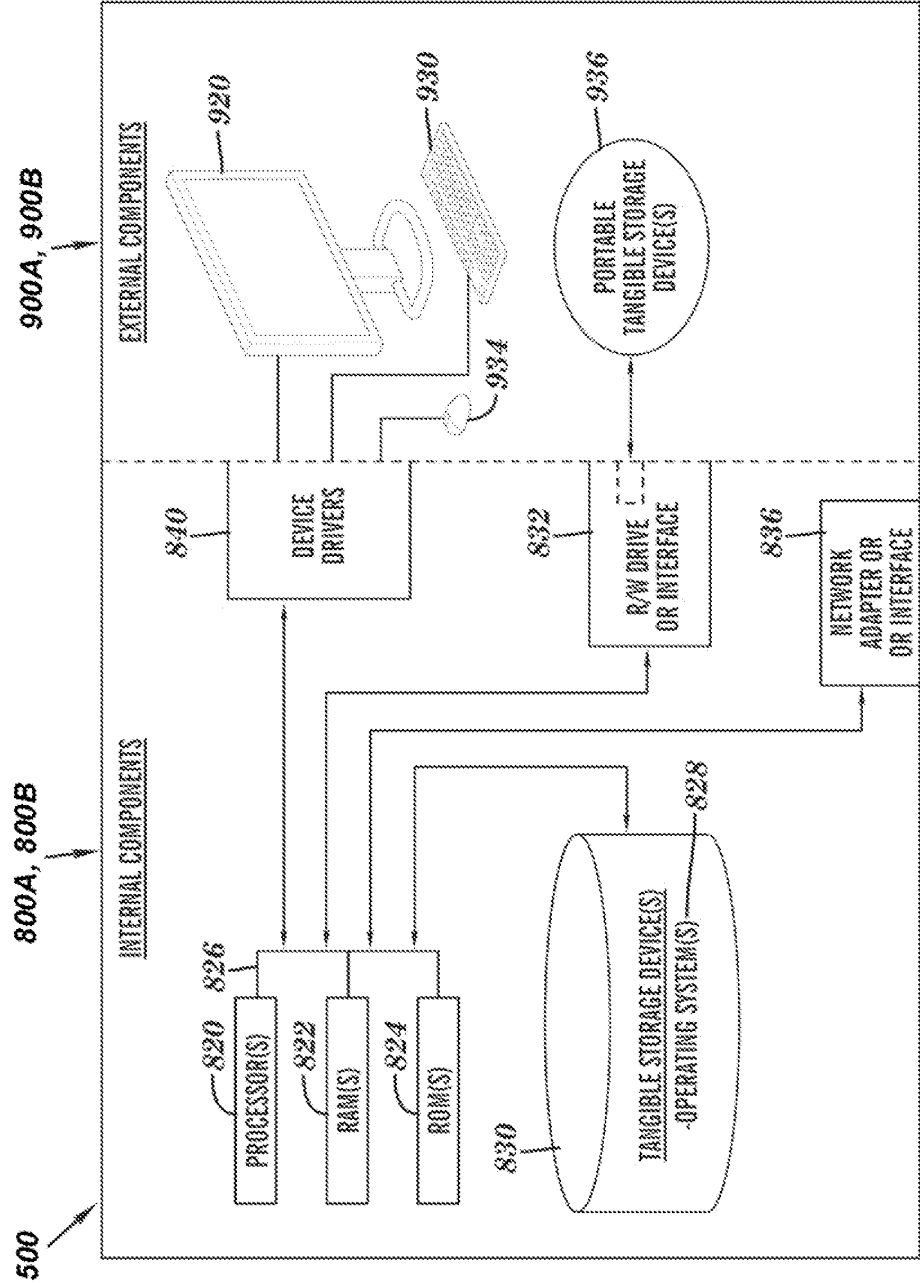


FIG. 5

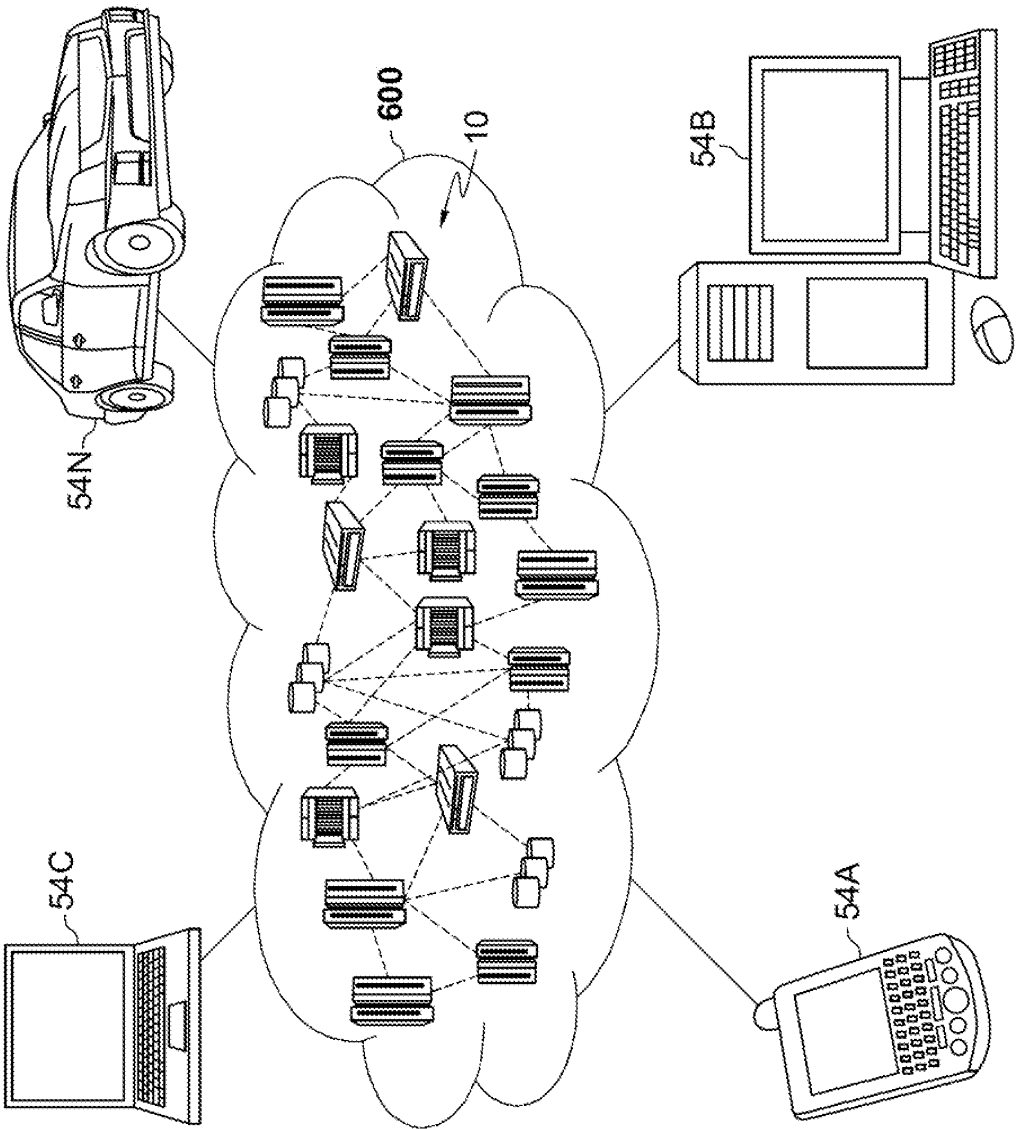


FIG. 6

700 →

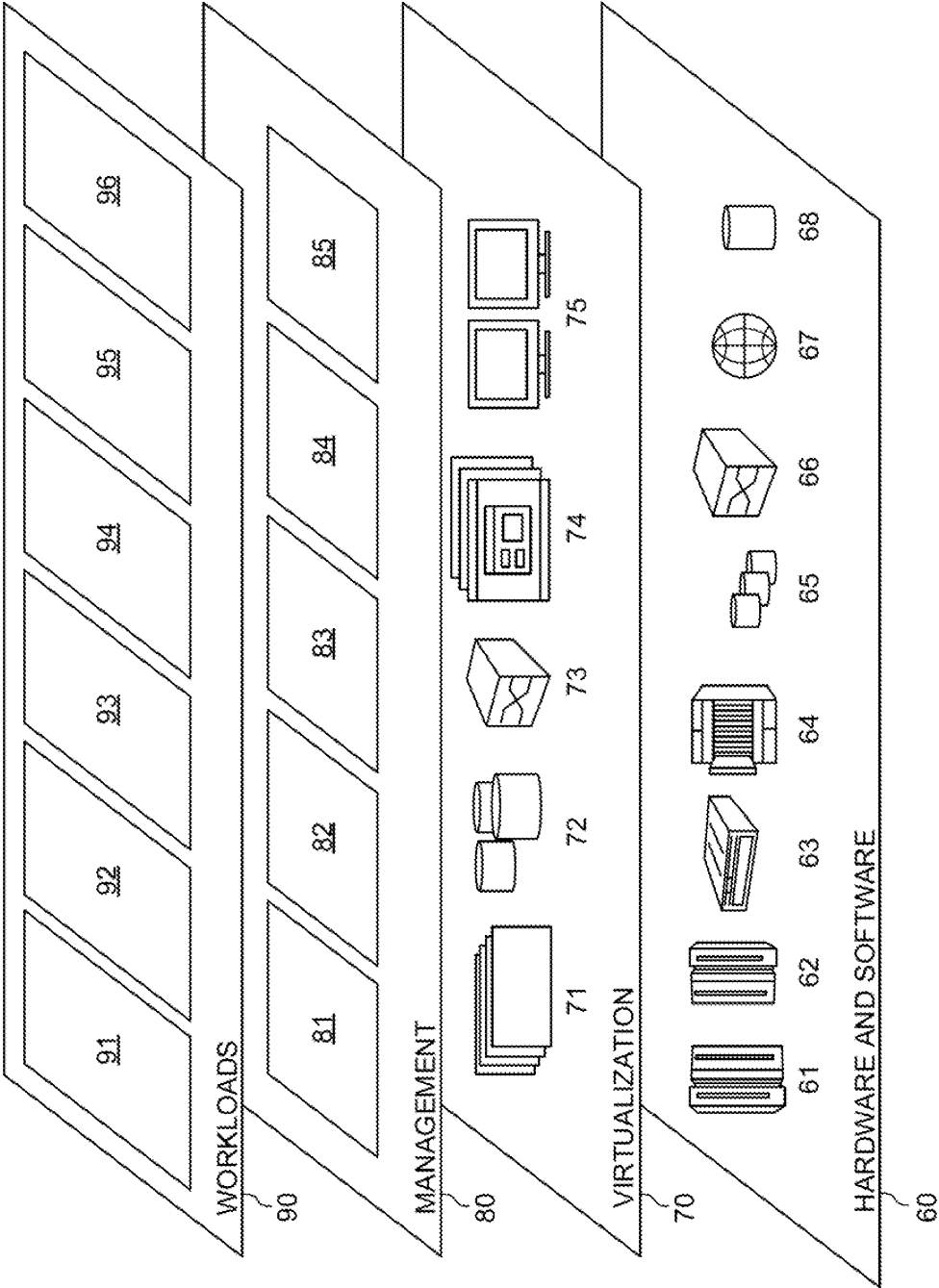


FIG. 7